

# WEST Search History

DATE: Sunday, March 22, 2009

<u>Hide?</u>	<u>Set Name</u>	<u>Query</u>	<u>Hit Count</u>
<i>DB=USPT; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L94	foot and L93	17
<input type="checkbox"/>	L93	float\$4 and L92	18
<input type="checkbox"/>	L92	"0" and L91	71
<input type="checkbox"/>	L91	robot\$6 and L90	92
<input type="checkbox"/>	L90	L89 and zmp (700/245 l700/246 l700/251 l700/253 l700/260 l700/261 318/568.1 l 318/568.12 l318/568.16 l318/568.17 l318/568.2 901/1 l901/9 l901/46 180.1).ccls.	92
<input type="checkbox"/>	L88	(("6962220")!.PN.) .p67-p150.	1
<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L87	robot\$6 and (walk\$3 or biped or humanoid or two legged) and (inlina\$6 or betn or tilt or deviat\$5 or obliqu\$5 or indirect\$4 or change direction or slope or slant)	6284
<input type="checkbox"/>	L86	('6711469' l'6697709' l'6567724' l'6505098' l'6493606' l'6480761' l'6330494' l'6289265' l'6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	16
<input type="checkbox"/>	L85	marc.xa. and legged and inclination	35
<input type="checkbox"/>	L84	marc.xa. and legged and inclinaiton	0
<input type="checkbox"/>	L83	('5404086')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L82	(edditing or updating) and (motion or traject\$4 or movement) and zmp and robot\$6	27
<input type="checkbox"/>	L81	(edditing or updating) same (motion or traject\$4 or movement) and zmp and robot\$6	12
<input type="checkbox"/>	L80	(edditing or updating) same (motion or traject\$4 or movement) and L79	10
<input type="checkbox"/>	L79	robot and zmp and yaw	169
<input type="checkbox"/>	L78	marc.xa. and zmp	47
<input type="checkbox"/>	L77	10/181500	3

<input type="checkbox"/>	L76	('6697709' l'6289265' l'6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	6
<input type="checkbox"/>	L75	marc.xa. and robot and zmp	47
<input type="checkbox"/>	L74	(motions or movement or displacement) and L73	122
<input type="checkbox"/>	L73	computer and L72	135
<input type="checkbox"/>	L72	record\$3 and L71	135
<input type="checkbox"/>	L71	(request or command) and L70	166
<input type="checkbox"/>	L70	L66 and L69	174
<input type="checkbox"/>	L69	execut\$5 and L68	312322
<input type="checkbox"/>	L68	run or L66  (6458772 or 6284156 or 6348461 or 6262044 or 6410586 or 6342245 or 6277877 or 6399557 or 3857856 or 5835892 or 6376445 or 6440911 or 6163111 or 5610305 or 5230889 or 4391489 or 4483594 or 6410749 or 4876009 or 6358945 or 6281227 or 6391397 or 6432994 or 4920120 or 5640119 or 5831440 or 6049212 or 6271251 or 4949326 or 5015815 or 5194938 or 4870247 or 6258470 or 6316465 or 6388989 or 4505827 or 5210848 or 5230070).pn.	1389091
<input type="checkbox"/>	L67	5874378 or 6374641 or 5384779 or 5523998 or 5537098 or 4260406 or 4293439 or 4386503 or 5179438 or 5208607 or 6275216 or 5534261 or 5640119 or 5831440 or 6049212 or 6271251 or 4949326 or 5015815 or 5194938 or 4870247 or 6258470 or 6316465 or 6388989 or 4505827 or 5210848 or 5230070).pn.	98
<input type="checkbox"/>	L66	(similar or "same") function and L65	201
<input type="checkbox"/>	L65	robot and control software and (chang\$3 or replac\$5)	2160
<input type="checkbox"/>	L64	('20050125099')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L63	(10/126774   10/970977   10/935607   10/919172   10/775845   10/732446   10/726597   10/683496   10/637890)	18
<input type="checkbox"/>	L62	(motion or displacement or trajector\$3) and L61	116
<input type="checkbox"/>	L61	(humanoid or two legged robot and human like robot) and zmp and comput\$5	119
<input type="checkbox"/>	L60	zmp and "approximately 0"	20
<i>DB=PGPB,USPT; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L59	(("20060106495")!.PN.).PGPB.   (("7119510")!.PN.).USPT.	2
<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L58	grasping and L57	6
<input type="checkbox"/>	L57	horizontal and vertical and L56	20
<input type="checkbox"/>	L56	signal and detection and L55	20
<input type="checkbox"/>	L55	distance and L54	23

<input type="checkbox"/>	L54	center and L53	28
<input type="checkbox"/>	L53	motion and L52	30
<input type="checkbox"/>	L52	gravity and L51	31
<input type="checkbox"/>	L51	floor reaction and L50	37
<input type="checkbox"/>	L50	foot and robot and ground contact and sensor and sole and joint and reaction and force and walk\$3	55
<i>DB=PGPB; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L49	L48	1
<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L48	10/553278	1
<input type="checkbox"/>	L47	L46 and robot	13
<input type="checkbox"/>	L46	metatarsophalangeal	540
<input type="checkbox"/>	L45	ground and contact and L43	26
<input type="checkbox"/>	L44	groung and contact and L43	0
<input type="checkbox"/>	L43	sensor and L42	34
<input type="checkbox"/>	L42	axis and L41	34
<input type="checkbox"/>	L41	soles and L40	34
<input type="checkbox"/>	L40	foot and L39	39
<input type="checkbox"/>	L39	L38 and coordinate	39
<input type="checkbox"/>	L38	position and orientation and L37	44
<input type="checkbox"/>	L37	(L9 or L10) and L36	85
<input type="checkbox"/>	L36	landed and landing and foot and robot\$6	153
<input type="checkbox"/>	L35	landed and landing and foot and footstep and robot\$6	6
<input type="checkbox"/>	L34	landed and landing and foot and footstep and (L9 or L10)	3
<input type="checkbox"/>	L33	landded and landing and foot and footstep and (L9 or L10)	0
<input type="checkbox"/>	L32	lannded and landing and foot and footstep and L23	0
<input type="checkbox"/>	L31	lannded and landing and foot and L30	0
<input type="checkbox"/>	L30	posture and L29	52
<input type="checkbox"/>	L29	gravity and coordinate and L28	53
<input type="checkbox"/>	L28	estimat\$3 and position and L27	62
<input type="checkbox"/>	L27	dynamics same model and L24	74

<input type="checkbox"/>	L26	dyanamics and L24	0
<input type="checkbox"/>	L25	dyanamics same model and L24	0
<input type="checkbox"/>	L24	L22 and L23	184
<input type="checkbox"/>	L23	movement or trajectory and L22	2694961
<input type="checkbox"/>	L22	floor and zmp and L9	193
<input type="checkbox"/>	L21	floor and zmp and L20	0
		(5024920   5173382   5490103   5557564   5901829   6201488   6521838   6518503   6695663   6592418   5733819   6027554   6663326   6694847   6685863   4252414   4588518   4561746   4719331   5118090   5434926   5419740   5558196   5527940   5716481).pn.	47
<input type="checkbox"/>	L19	motion pattern and L17	2
<input type="checkbox"/>	L18	motion pattern and stor\$3 and L17	0
<input type="checkbox"/>	L17	freedom and L16	5
<input type="checkbox"/>	L16	L14 and L15	6
<input type="checkbox"/>	L15	L14 and gait or gate	1273890
		('6580969'   '6493606'   '6463356'   '6289265'   '6243623'   '5872893'   '5841258'   '5838130'   '5594644'   'EP 1136193A'   'EP 1103451A')!.ABPN1, NRPN,PN,TBAN,WKU.	18
<input type="checkbox"/>	L13	('20030019671'   '20020138359'   '6591923'   '6458011')!.ABPN1,NRPN,PN, TBAN,WKU.	7
<input type="checkbox"/>	L12	(legged robot or pet robot or humanoid near10 robot) motion and pattern	13
<input type="checkbox"/>	L11	(legged robot or pet robot or humanoid near10 robot) motion and pattern and L10	0
		(6252544   6493606   6243623   6289265   5673367   5355064   5455497   5325031   5357433   5594644   6580969   6718231   5504841   5842533   4621333   4633059   4987527   5937398   6064168   6429812   6584377   5259064   5349646   5946041   4540211   4762261   5273296   5616917   5627440   5794621   6059092   6059092   6068201   6456728   6505098   6711469   5402050   5525883   5841258   6463356   4614504   5040626   5343397   5369346   5378969   5644204   5672924   5838130   5872893   6229552).pn.	97
		(700/245   700/246   700/251   700/253   700/260   700/261 or 318/568.1   318/568.12   318/568.16   318/568.17   318/568.2 or 901/1   901/9   901/46 or 180/8.1   180/8.6   180/65.1 or 701/23 or 320/116   320/120 or 446/376   446/384).ccls.	10678
<input type="checkbox"/>	L8	6580969.pn.	2

□	L7	11/456454	2
□	L6	10/511608	1
□	L5	coordinate and L4	7
□	L4	"foot-sole" and L2	22
□	L3	"based on" and L2	48
□	L2	foot same position same sole	4883
□	L1	takenaka.in. and floor reaction force and position	102

END OF SEARCH HISTORY